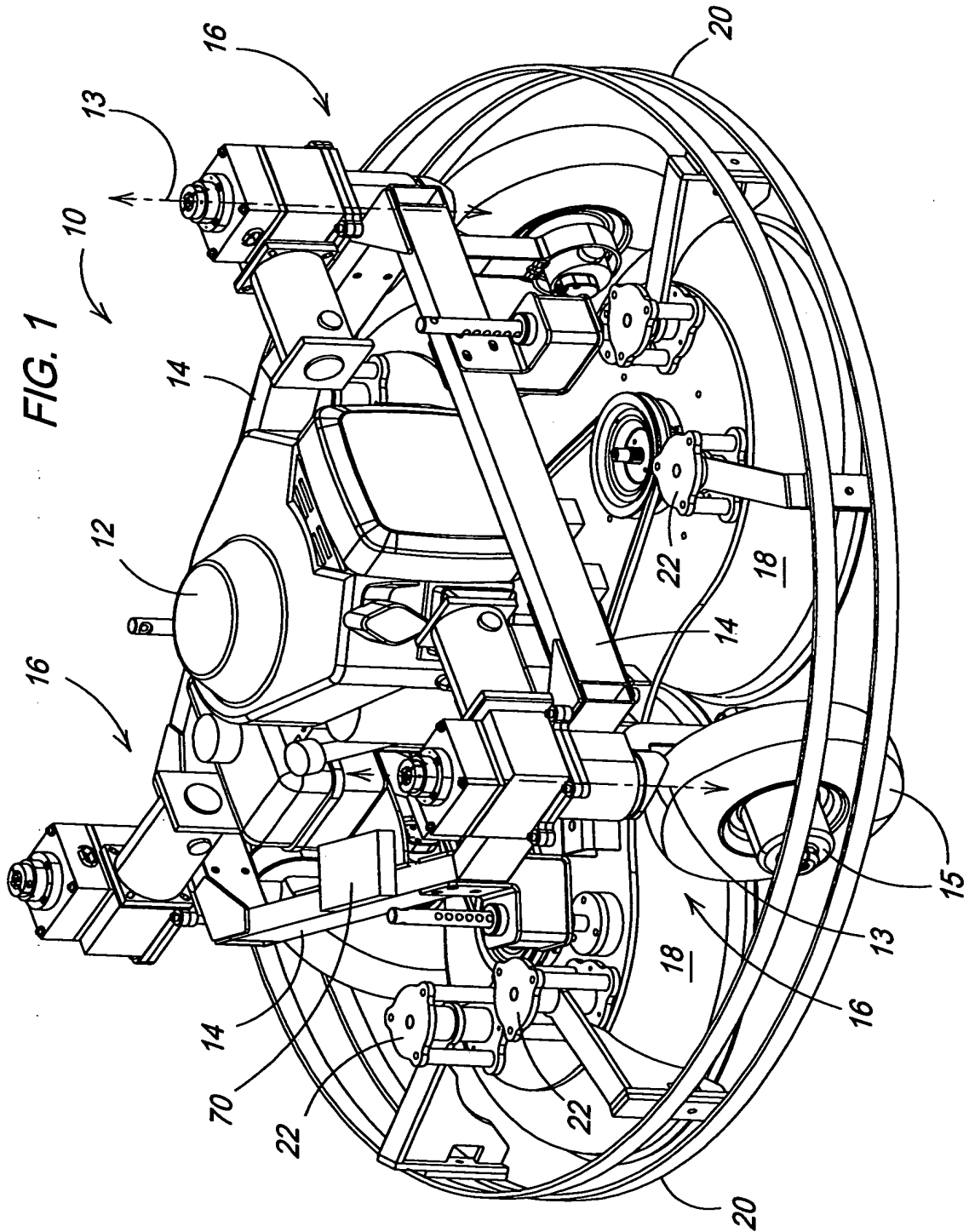
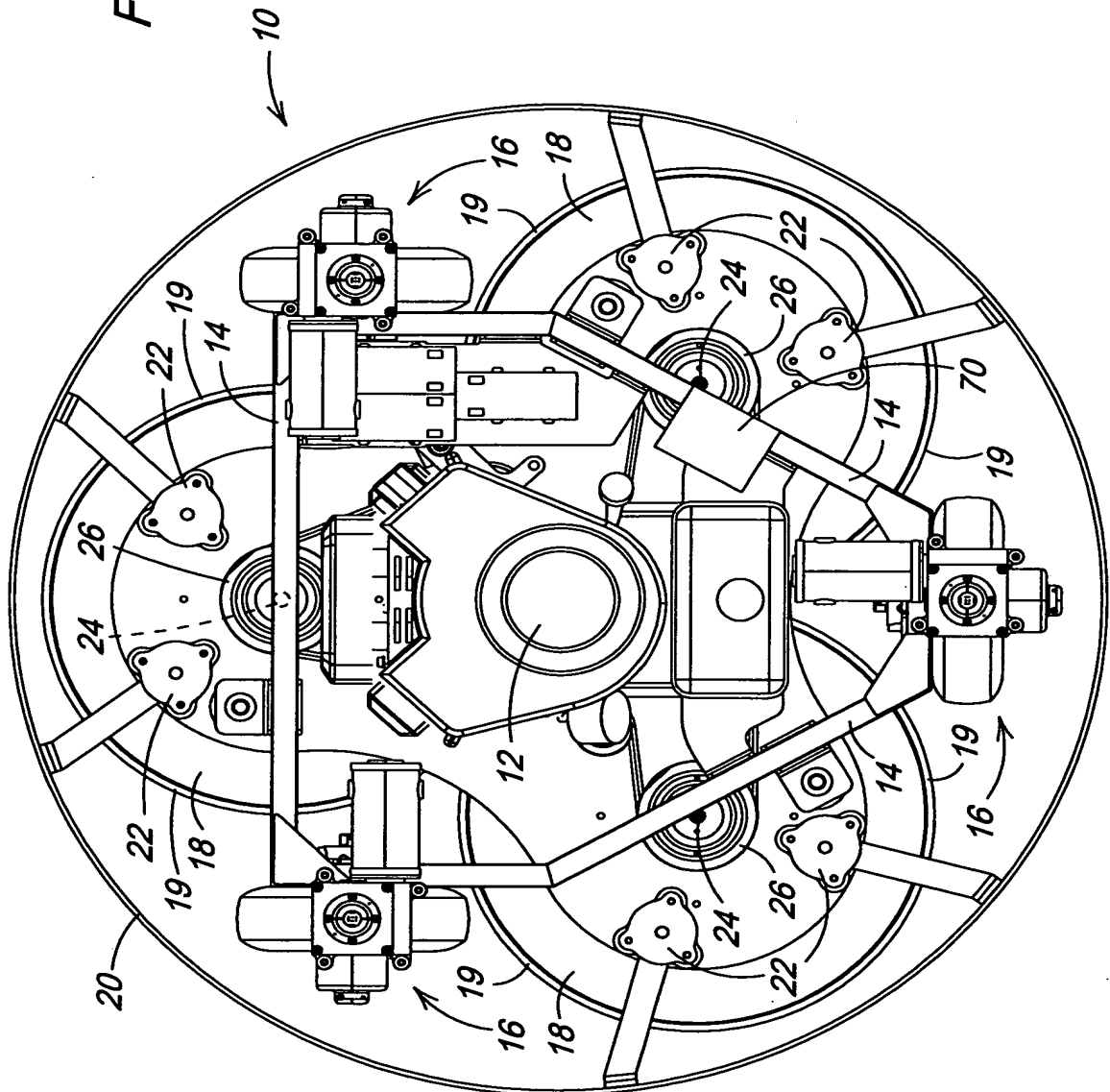


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FIG. 2

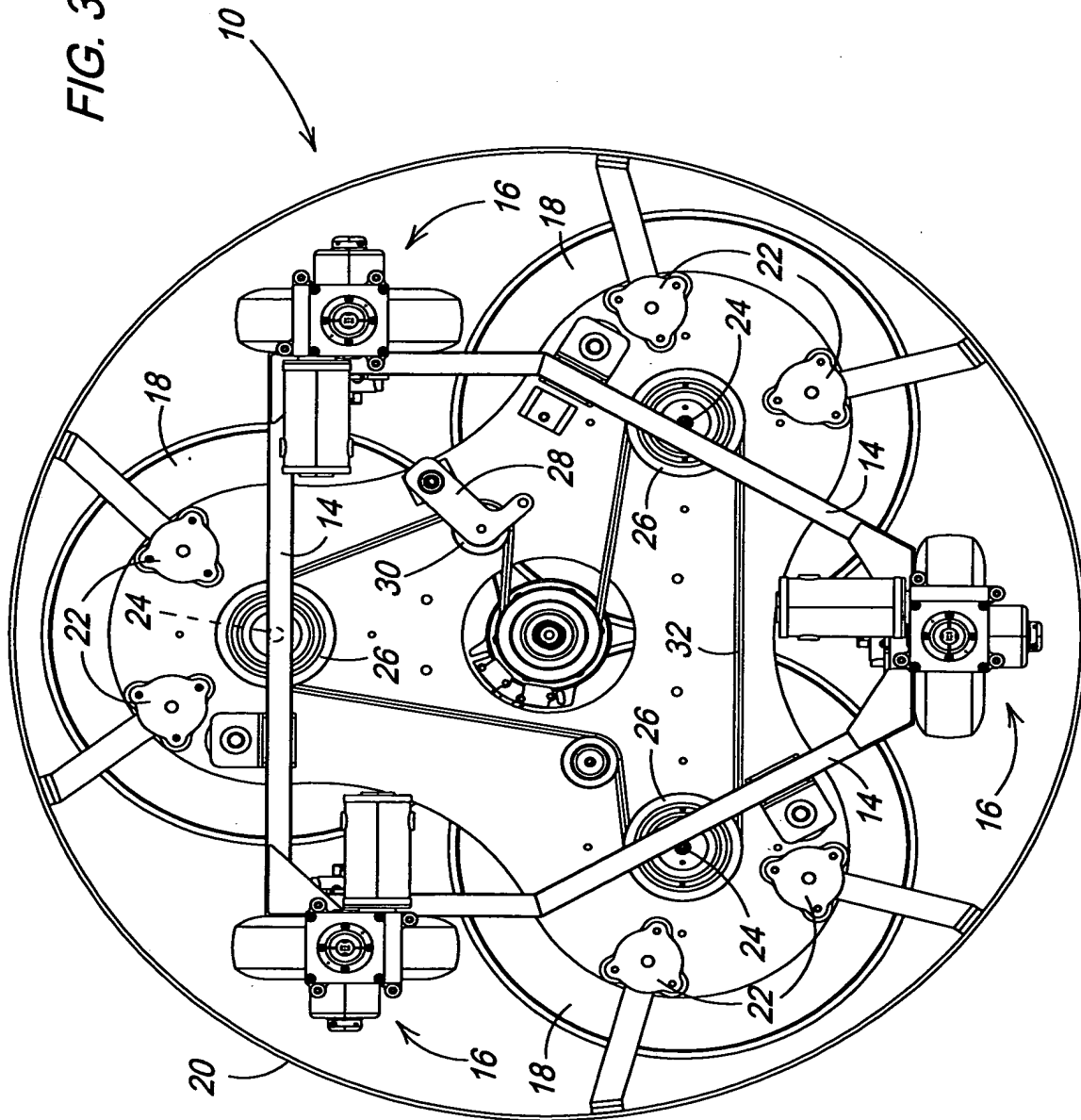


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FIG. 3



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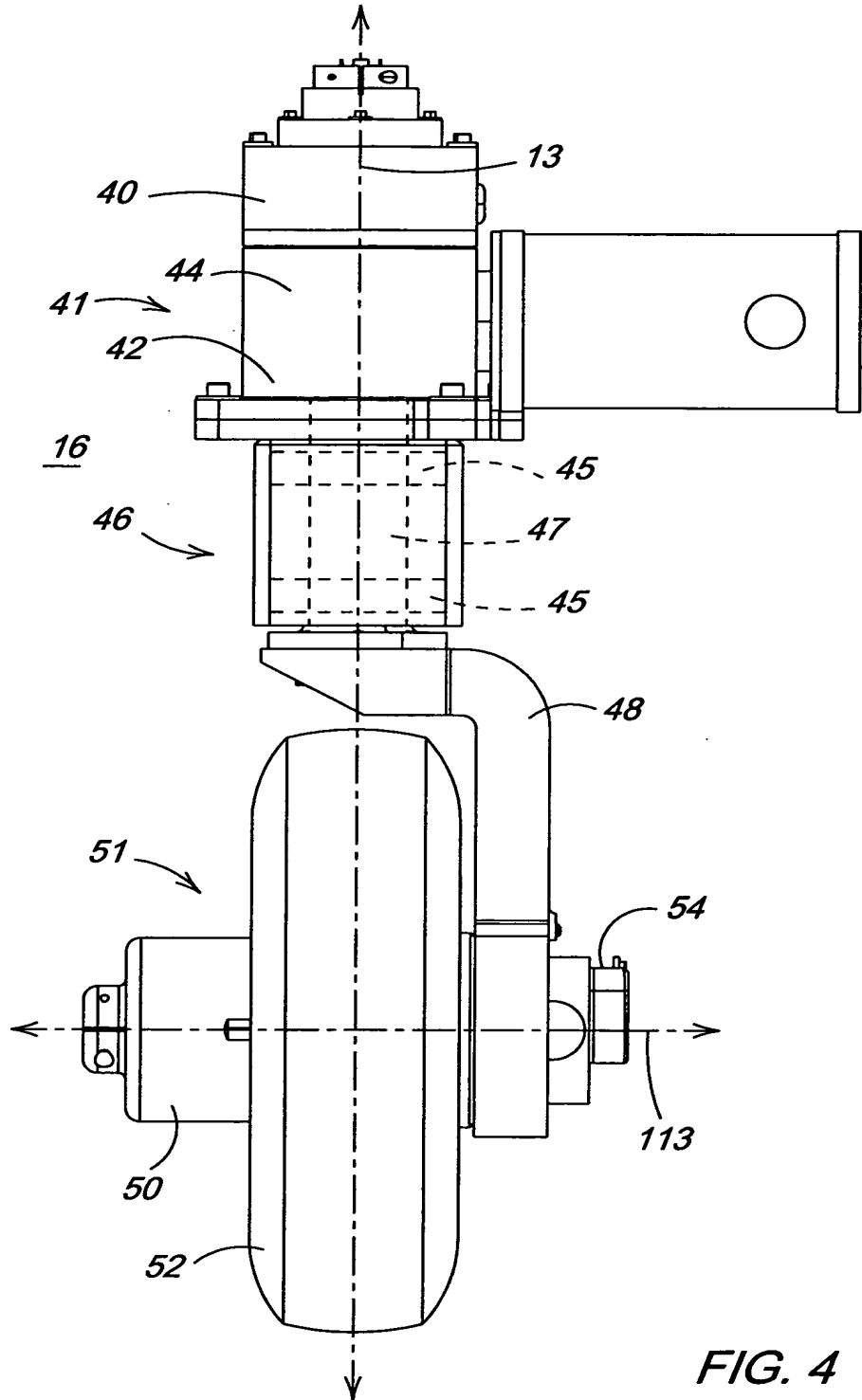
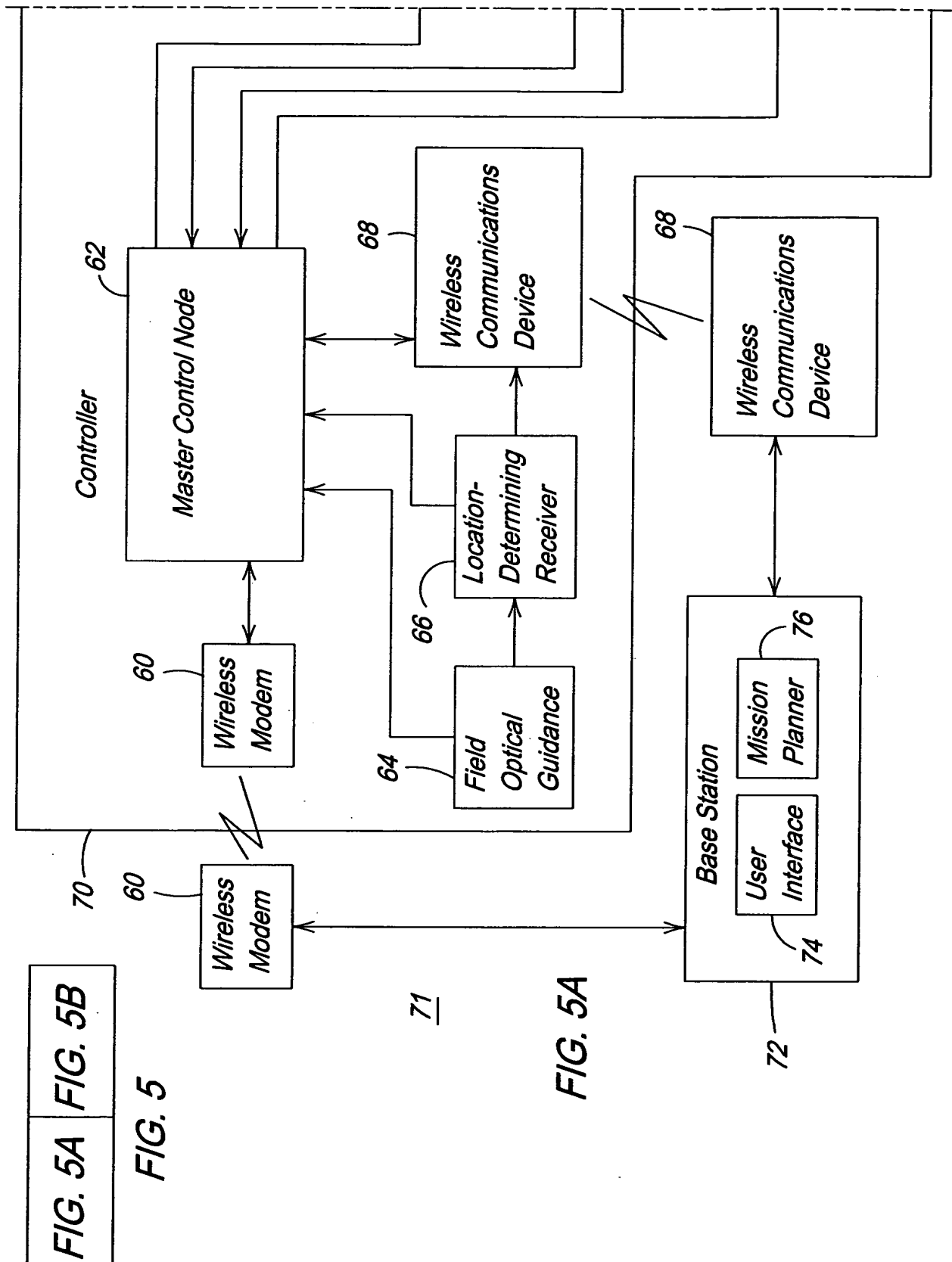
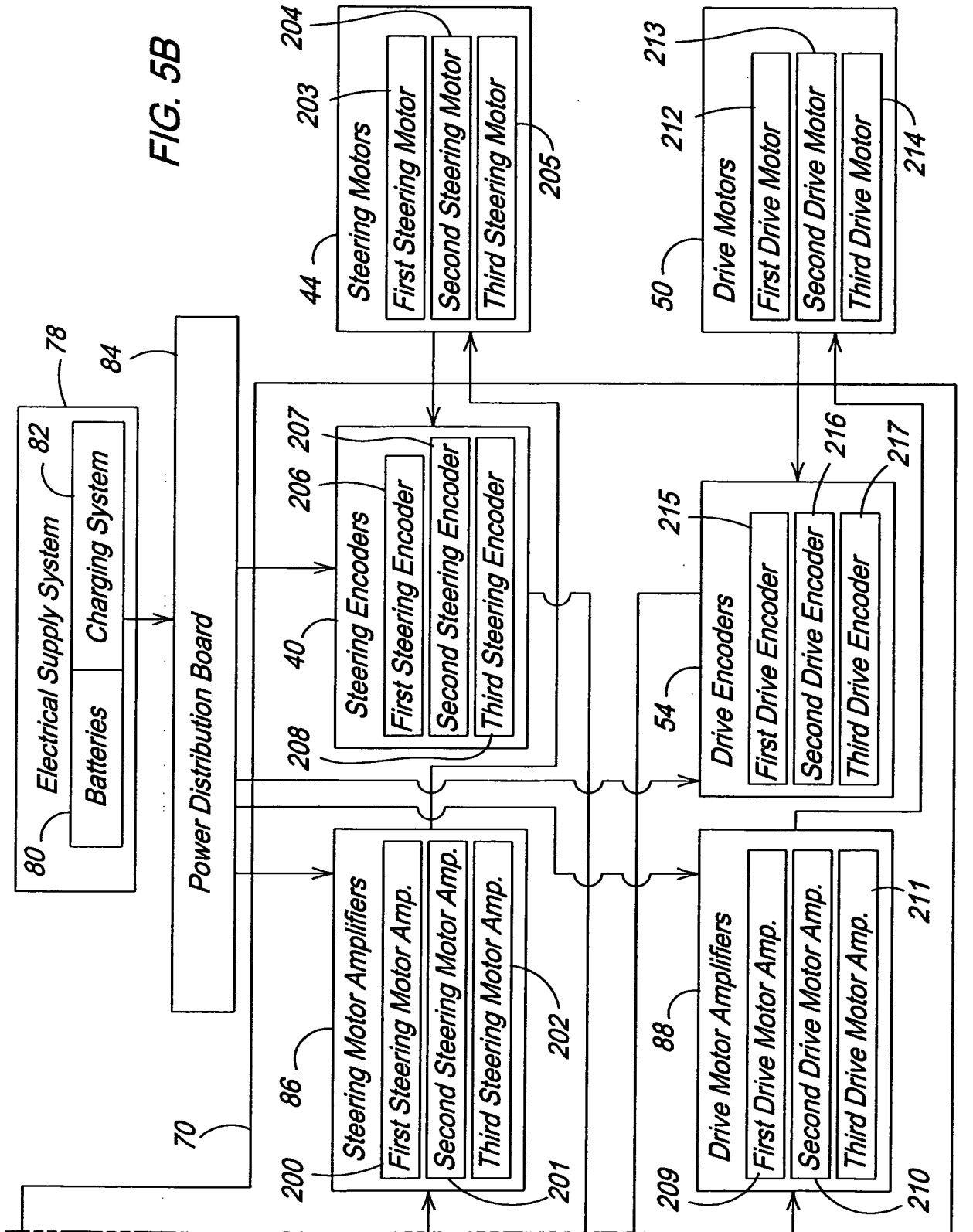


FIG. 4



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FIG. 5B



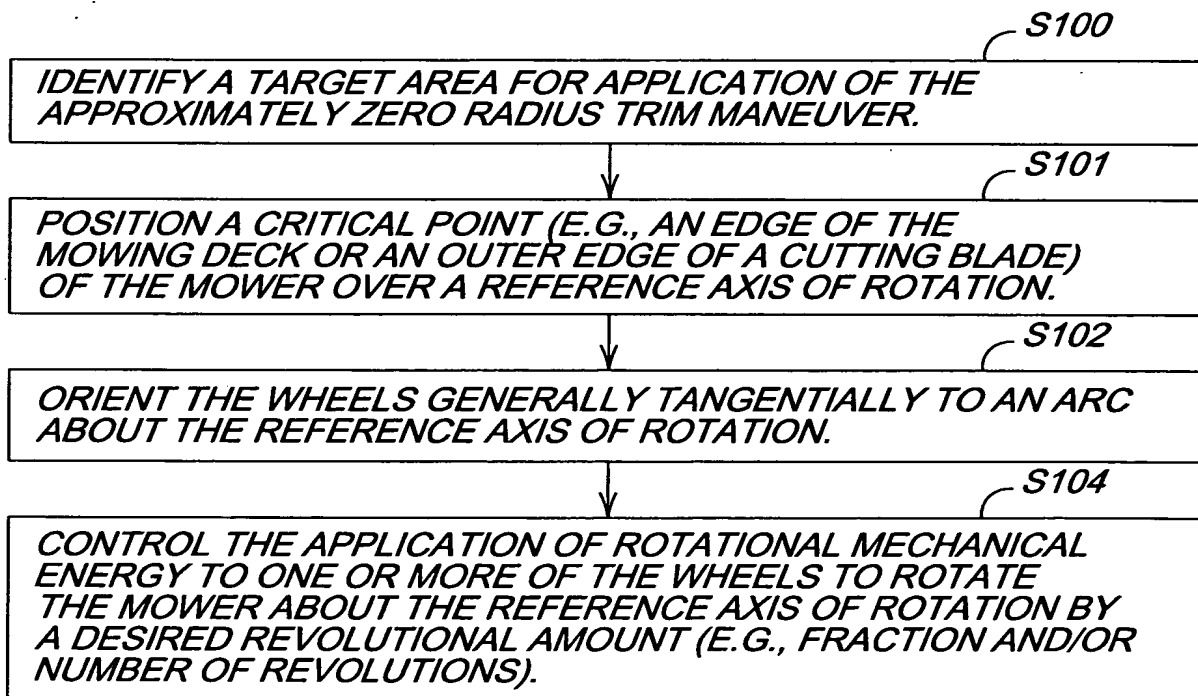
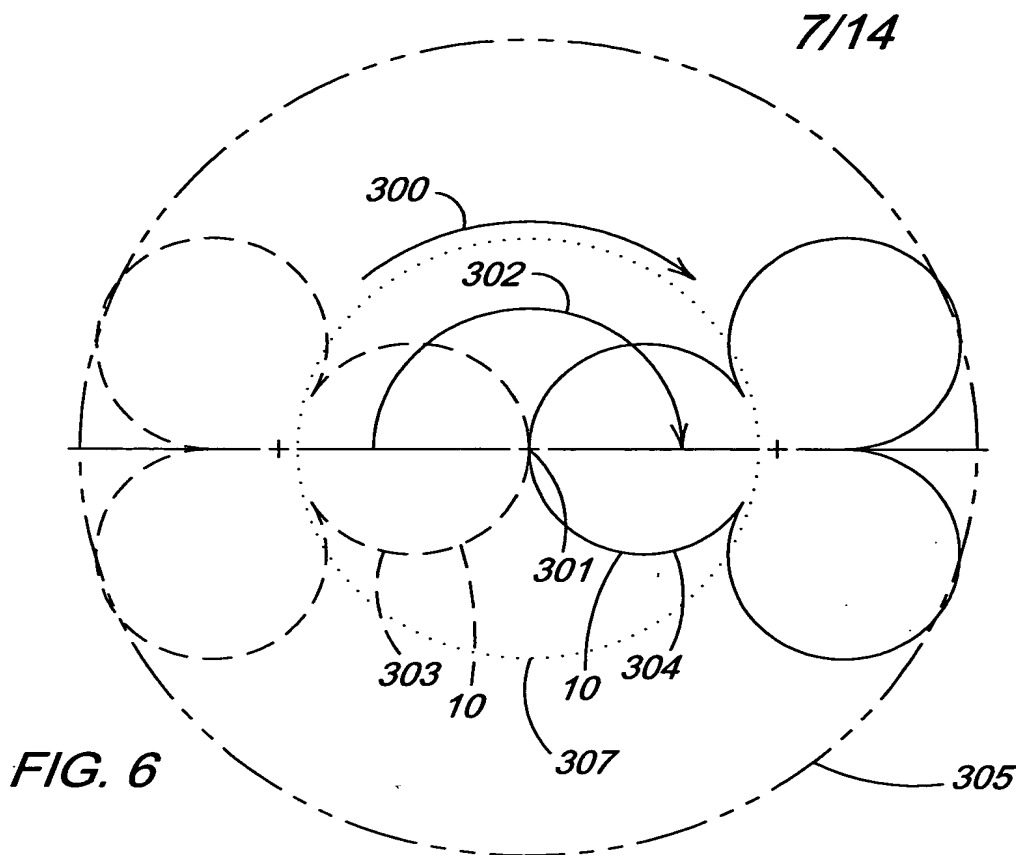
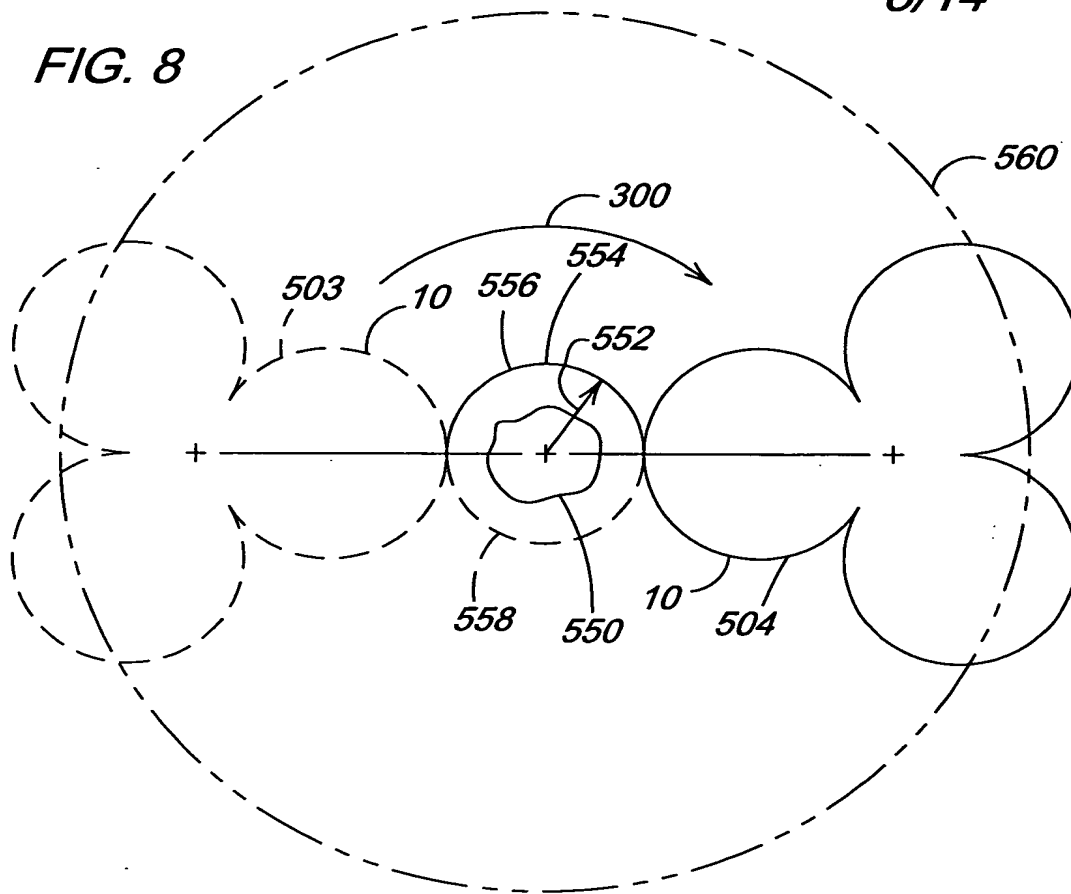


FIG. 7

FIG. 8



IDENTIFY A TARGET AREA FOR APPLICATION OF THE NEAR ZERO RADIUS TRIM OR GREATER THAN ZERO RADIUS TRIM MANEUVER.

POSITION A CRITICAL POINT OF THE MOWING DECK OR AN OUTER PERIPHERY OVER A REFERENCE ARC.

ALIGN THE STEERED DIRECTION OF THE WHEELS TO BE GENERALLY TANGENTIAL TO RESPECTIVE ARCS THAT ARE GENERALLY CONCENTRIC WITH RESPECT TO THE REFERENCE ARC.

CONTROL THE APPLICATION OF ROTATIONAL MECHANICAL ENERGY TO ONE OR MORE OF THE WHEELS TO ROTATE THE MOWER ABOUT THE OBJECT BY A DESIRED FRACTION AND/OR NUMBER OF REVOLUTIONS.

FIG. 9

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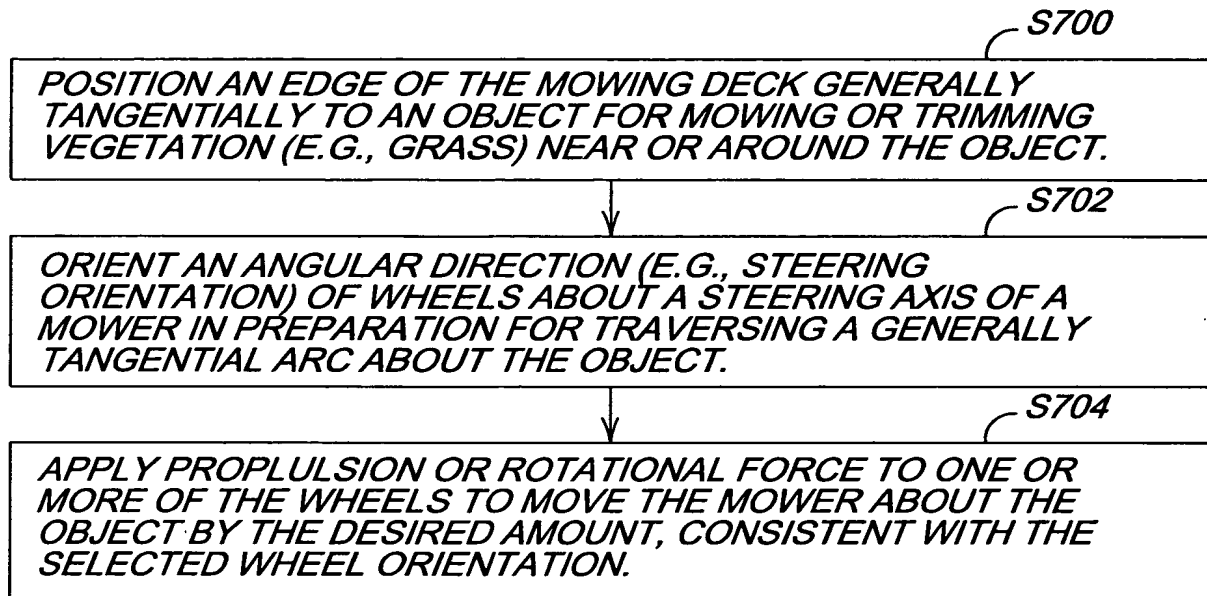


FIG. 10

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FIG. 11

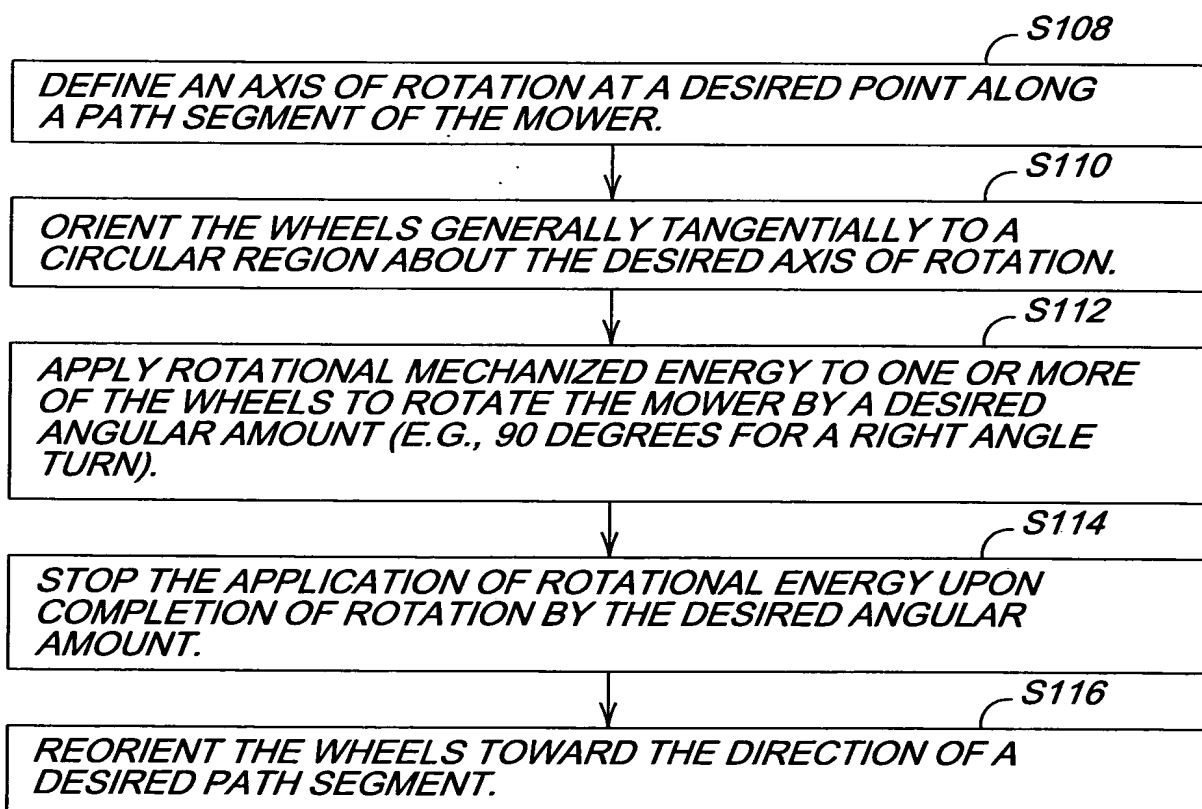
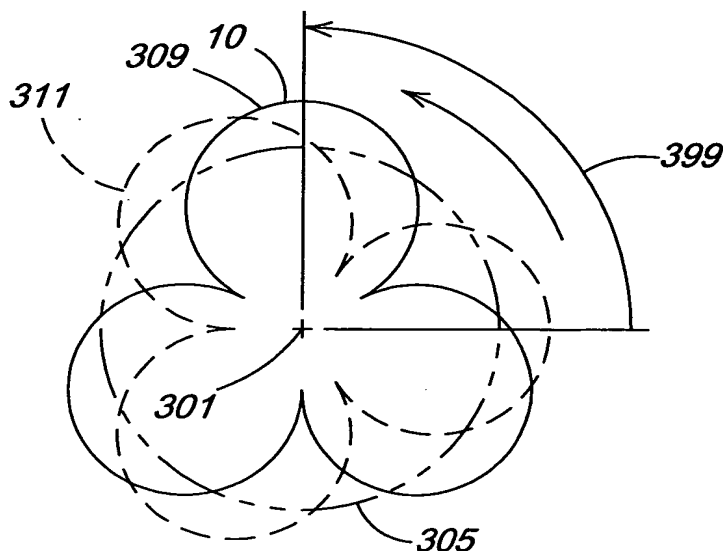


FIG. 12

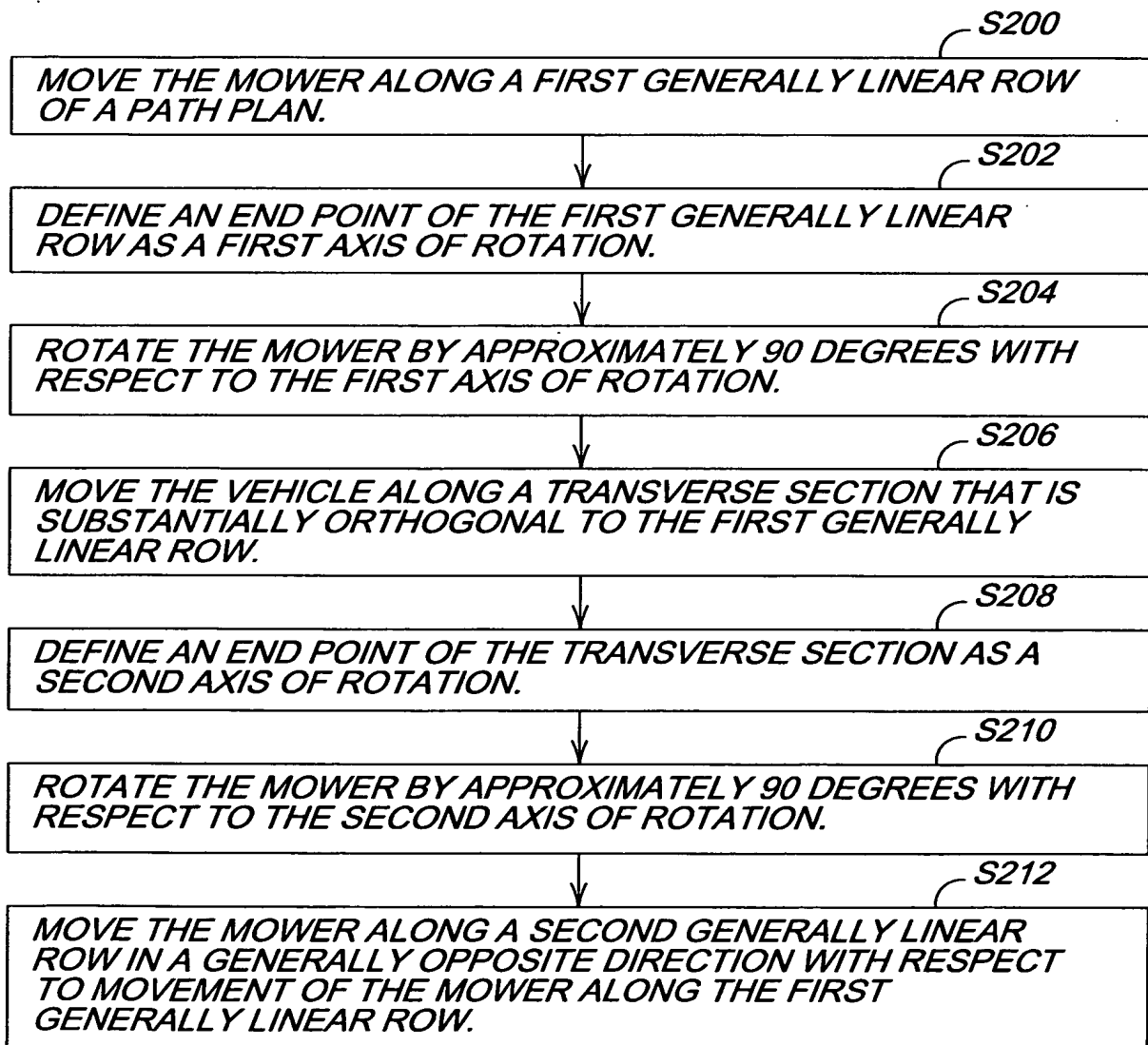
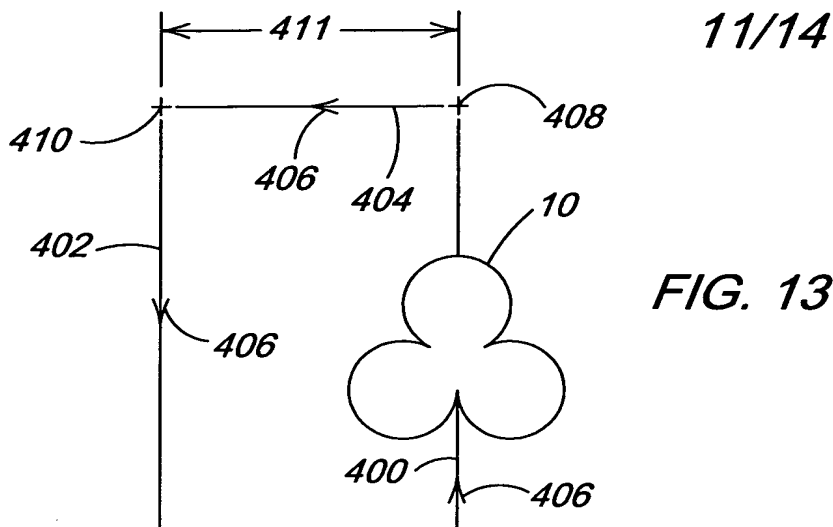
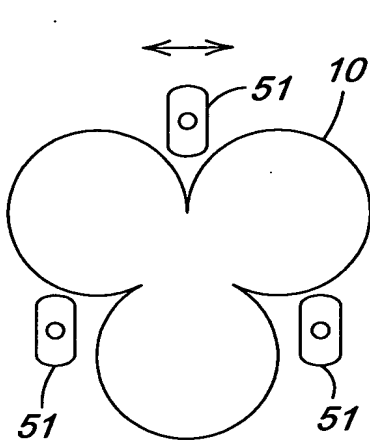
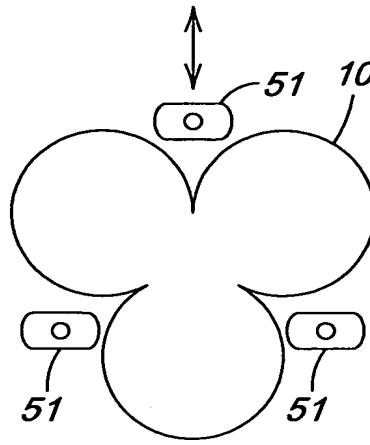


FIG. 14

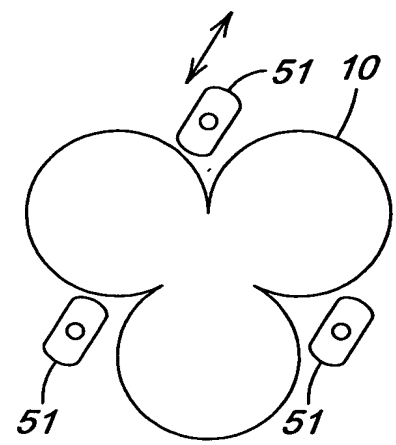
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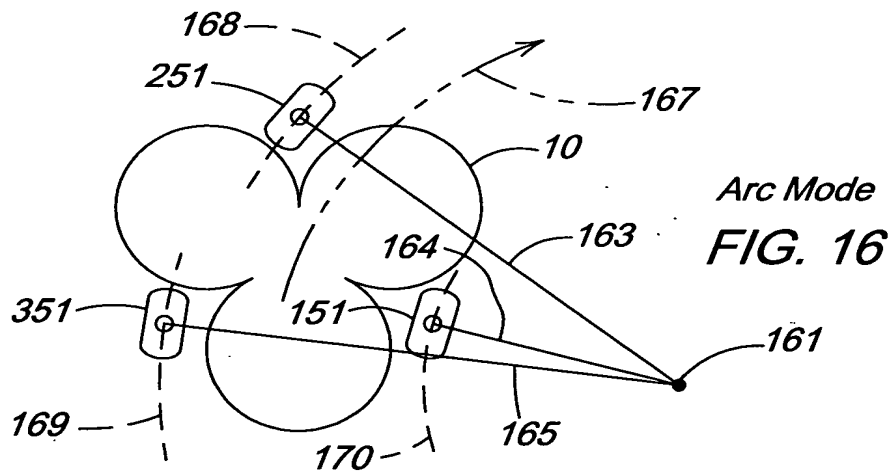
Linear Mode
 FIG. 15A



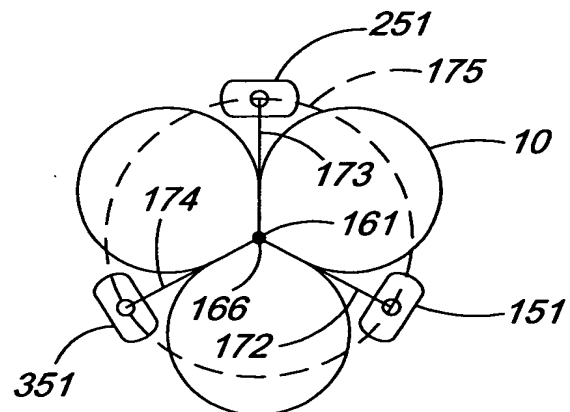
Linear Mode
 FIG. 15B



Linear Mode
 FIG. 15C

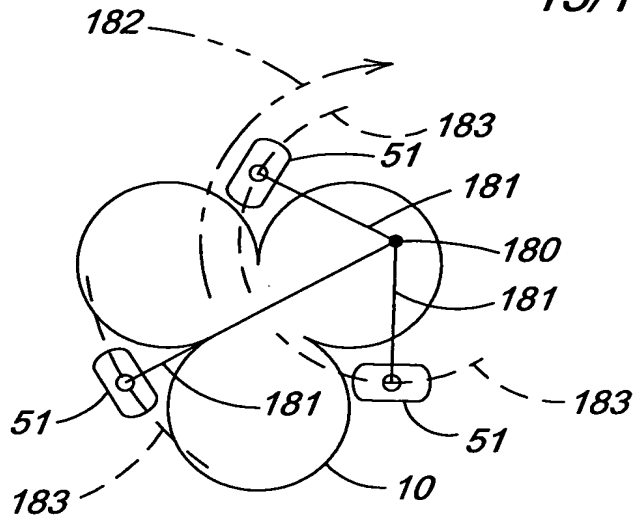


Arc Mode
 FIG. 16

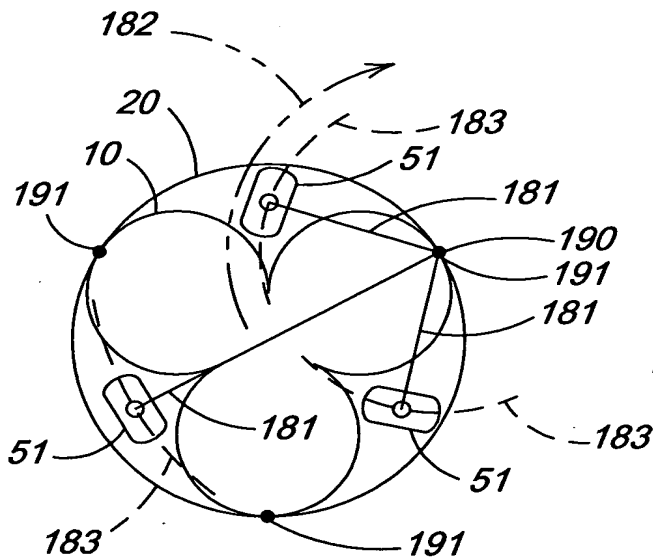


Rotating Mode
 FIG. 17

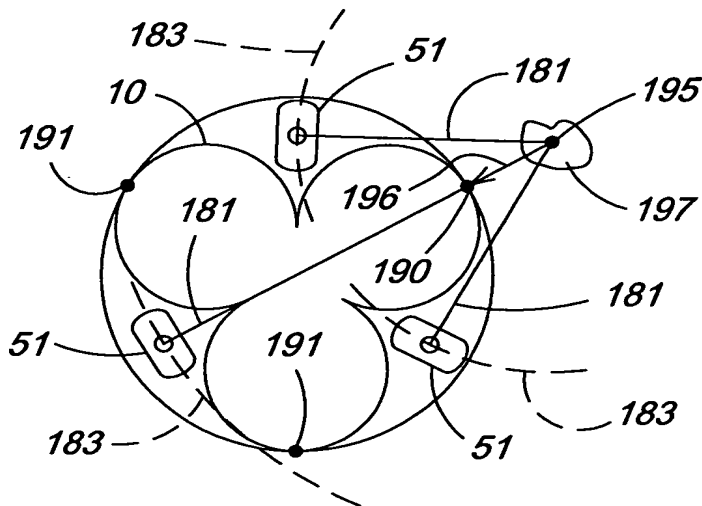
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Interior Arc Mode
FIG. 18



Trim Mode (Zero Radius)
FIG. 19



Trim Mode
 (Greater Than Zero Radius)
FIG. 20

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FIG. 21

Path Plan Data

1st Path Segment

Starting Coordinate (X_1, Y_1)

Destination Coordinate (X_2, Y_2)

Mode (E.g., Linear, Arc, Rotating or Combination) (M_1)

Reference Point Coordinate (Where Applicable) (R_1)

2nd Path Segment

Starting Coordinate (X_2, Y_2)

Destination Coordinate (X_3, Y_3)

Mode (M_2)

Reference Point (R_2)

⋮

Nth Path Segment

Starting Coordinate (X_N, Y_N)

Destination Coordinate (X_{N+1}, Y_{N+1})

Mode (M_N)

Reference Point (R_N)

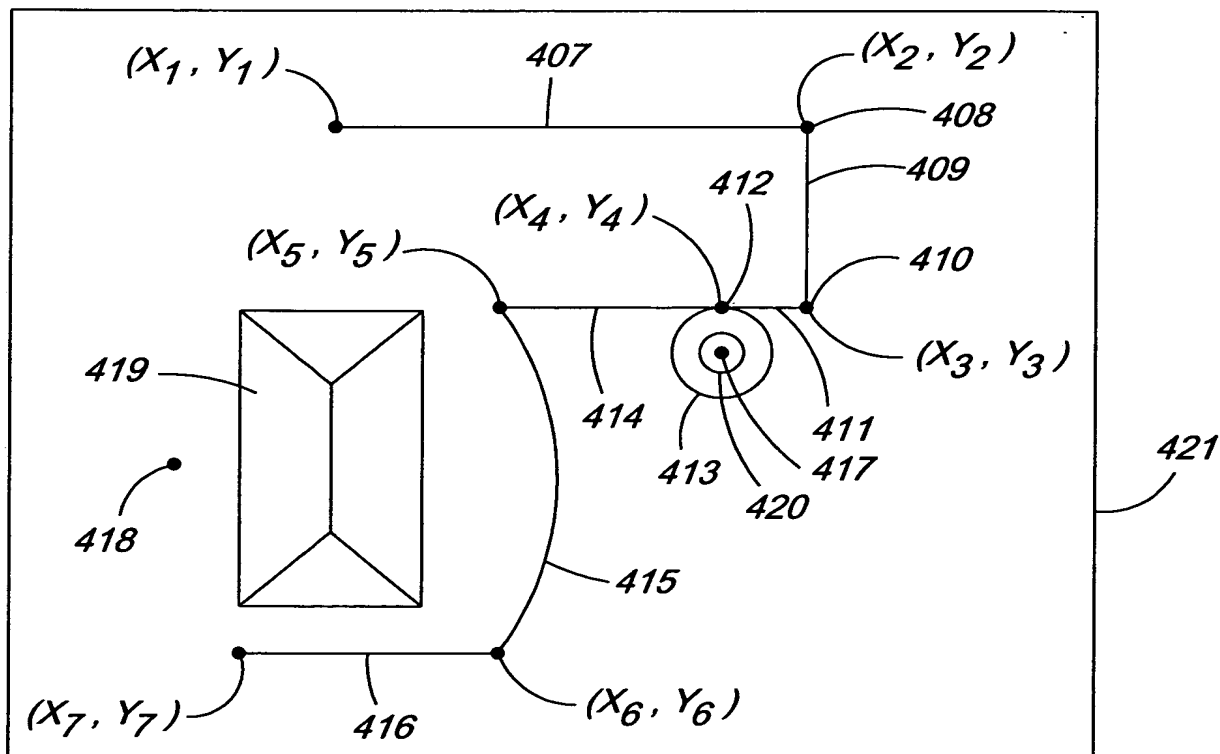


FIG. 22